In the Abstract:

Please amend the abstract as follows. A clean copy of the abstract is submitted herewith on a separate sheet.

A method for programming an industrial robot having a tool, to perform a process on an object while following a robot path defined by a number of waypoints. The method comprises: includes obtaining configuration data including configuration data for the tool and tool, configuration data for the robot path and information about the position and orientation of the object in relation to the robot, obtaining a sequence of waypoints, which defines the process in relation to the object, the waypoints comprises information about desired positions of the tool in relation to the object and desired positions of process events in relation to the object, obtaining at least one distance for adjusting the position of a waypoint, deciding whether an obtained waypoint should be modified or not, based on the obtained information about the waypoints, generating a modified sequence of waypoints by modifying the waypoints in the obtained sequence of waypoints, based on said the decision, the obtained distance and the obtained information about the waypoints and generating the actual robot path based on the modified sequence of waypoints and the obtained configuration data.

(Fig. 6)

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